

UNITED STATES PATENT AND TRADEMARK OFFICE  
**CERTIFICATE OF CORRECTION**

PATENT NO. : 6,780,536 B2  
 DATED : August 24, 2004  
 INVENTOR(S) : Debe, Mark K. et al.

Page 1 of 2

It is certified that error appears in the above-identified patent and that said Letters Patent is hereby corrected as shown below:

Column 10,

Lines 10-17, replace the formula with the following:

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since  $\cos \theta = \frac{x_0}{g}$  in Fig. 2 above.

Also from Fig. 2,  $y_0 = 2 \cdot x_0 \tan \theta + w$ . Replacing  $y_0$  in (2) with this gives, from (1),

$$(3) \quad U_r(x) = -\frac{K_L}{\mu} \cdot \frac{\Delta P}{N(w+2L)} \frac{(w+2 \frac{x_0}{\cos \theta})}{(w+2 x_0 \tan \theta)} \quad --.$$

Column 11,

Lines 37-42, replace the formula with the following:

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$$(5) \quad U_{i,r}(x) = -\frac{K_L}{\mu} \cdot \frac{\Delta P_i}{(w_i+2L_i)} \frac{(w_i+2 \frac{x_0}{\cos \theta_i})}{(w_i+2 x_0 \tan \theta_i)}, \quad \text{where } \Delta P = \sum_{i=1}^N \Delta P_i \quad --.$$

Line 67, replace the formula with the following:

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$$p_i(O_2) = \frac{p_{i,O_2} \cdot M_w}{RT} \quad \text{at that point of loop } i: \quad --.$$

Column 12,

Lines 1-5, replace the formula with the following:

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$$(7) \quad \frac{dm_{i,O_2}}{dA}(x=L) = \frac{-K_L M_w}{RT \mu} \frac{p_{i,O_2} \Delta P_i}{2L_i \sin \theta_i}, \quad --.$$

Line 8, replace the formula with the following:

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$\Delta P_i$  and  $p_{i,O_2}$  --.

Line 20, replace the formula with the following:

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For  $p_{i,O_2}$  --.

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It is certified that error appears in the above-identified patent and that said Letters Patent is hereby corrected as shown below:

Column 12 (cont'd).

Lines 30-32, replace the formula with the following:

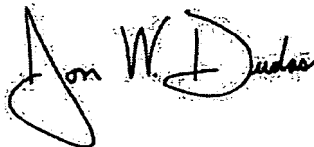
$$\text{-- (9) } p_{i,O_2} = P_{in}(O_2) \left( 1 - \frac{i}{N\eta} \right) \text{ --.}$$

Column 15,

Line 21, delete "zig-zig" and insert in place thereof -- zig-zag --.

Signed and Sealed this

Twenty-third Day of August, 2005



JON W. DUDAS  
*Director of the United States Patent and Trademark Office*